

1/24

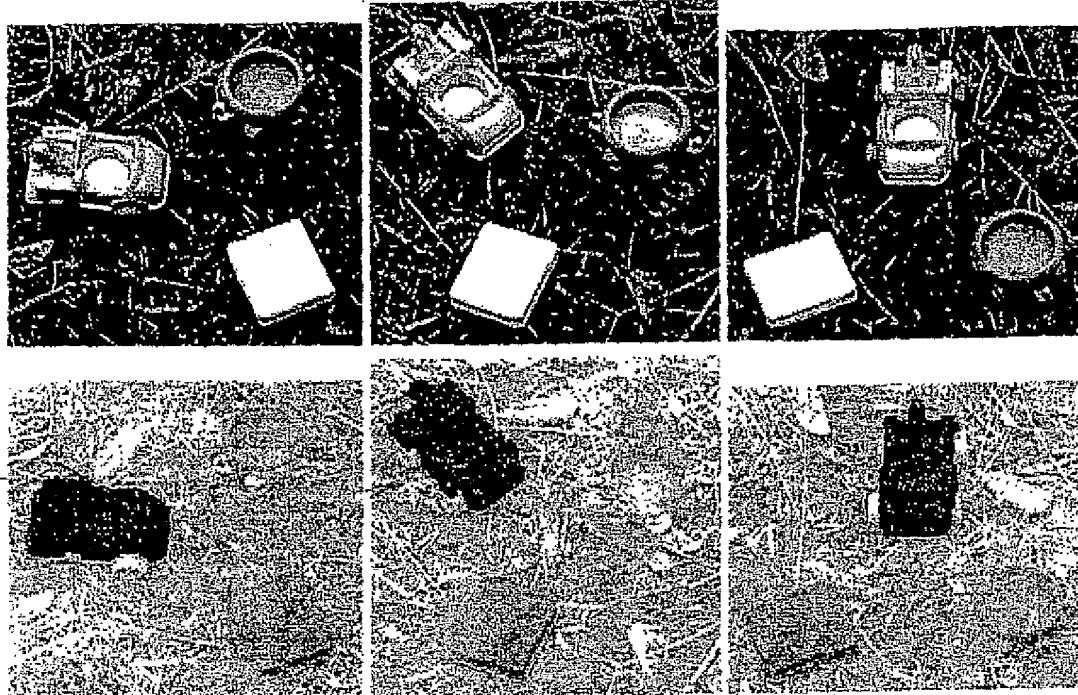


Figure 1 Original images separated by a 3D rotation of 45° and 90° (top) and matching results (bottom), displayed in same colors.

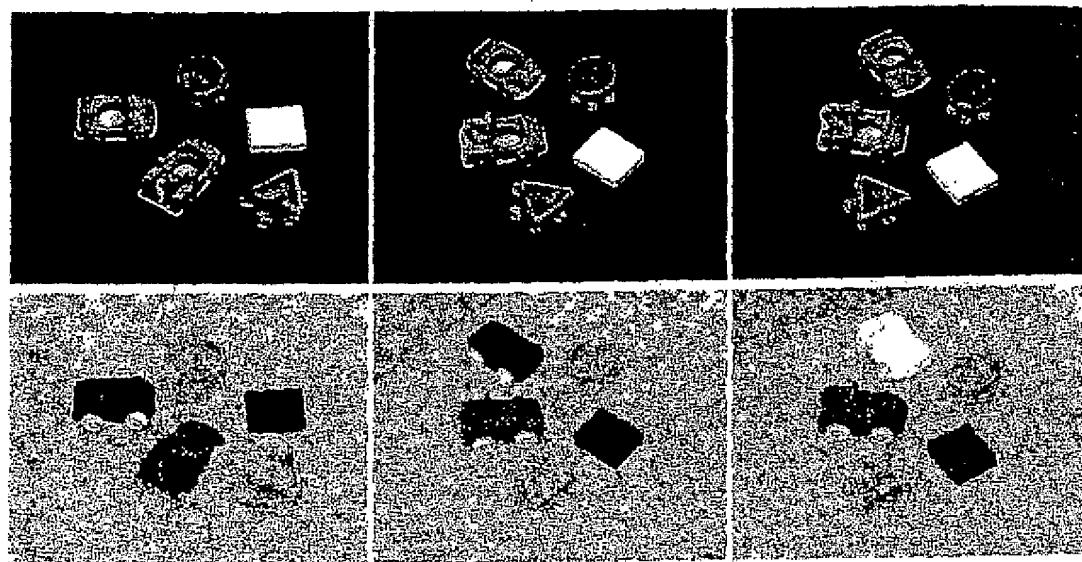


Figure 2 Original images separated by a 3D rotation of 45° and 60° (top) and matching results (bottom).

2/24

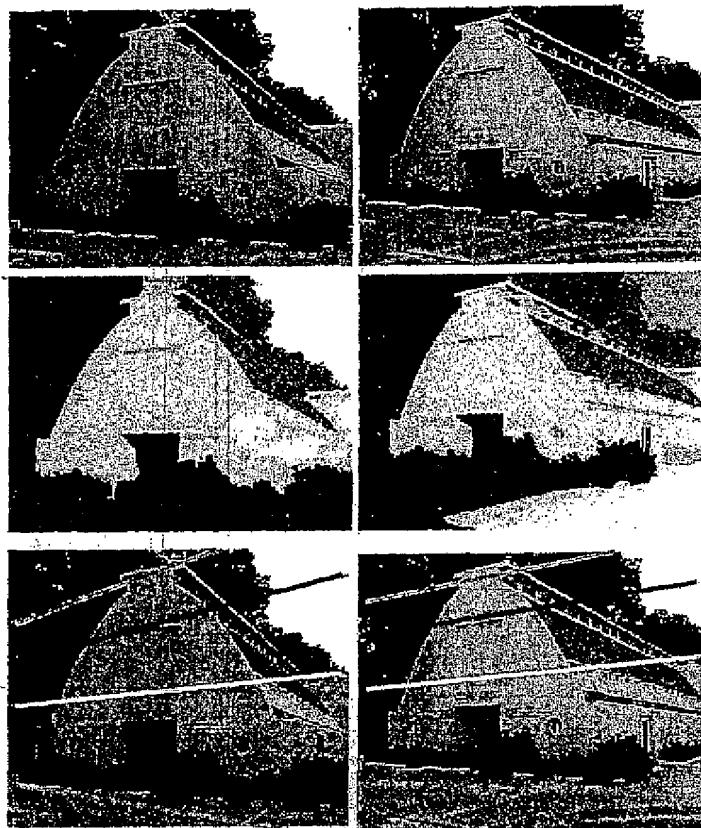


Figure 3: Original images (top), matched aggregates (middle) and epipolar lines (bottom).

3/24

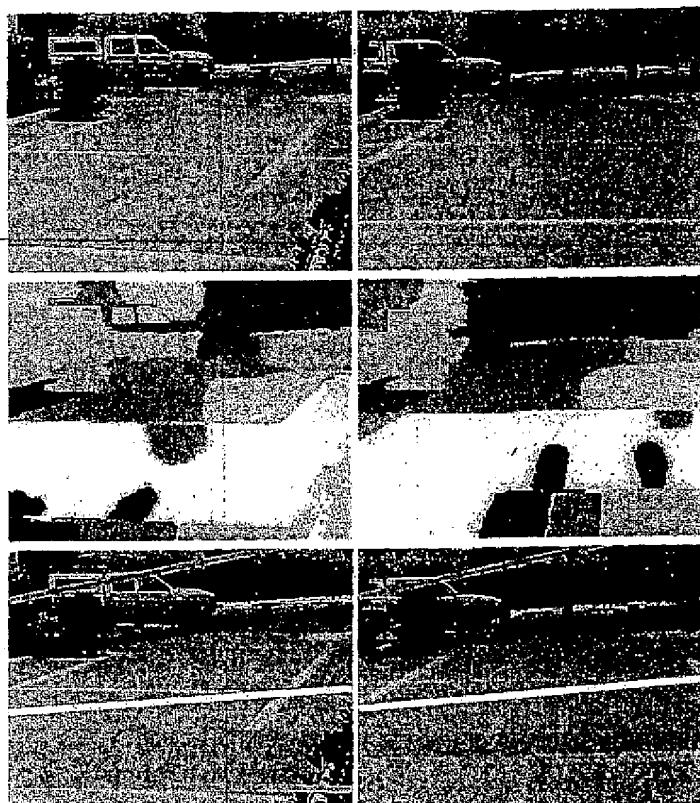


Figure 4 Original images (top), matched aggregates (middle) and epipolar lines (bottom).

4/24

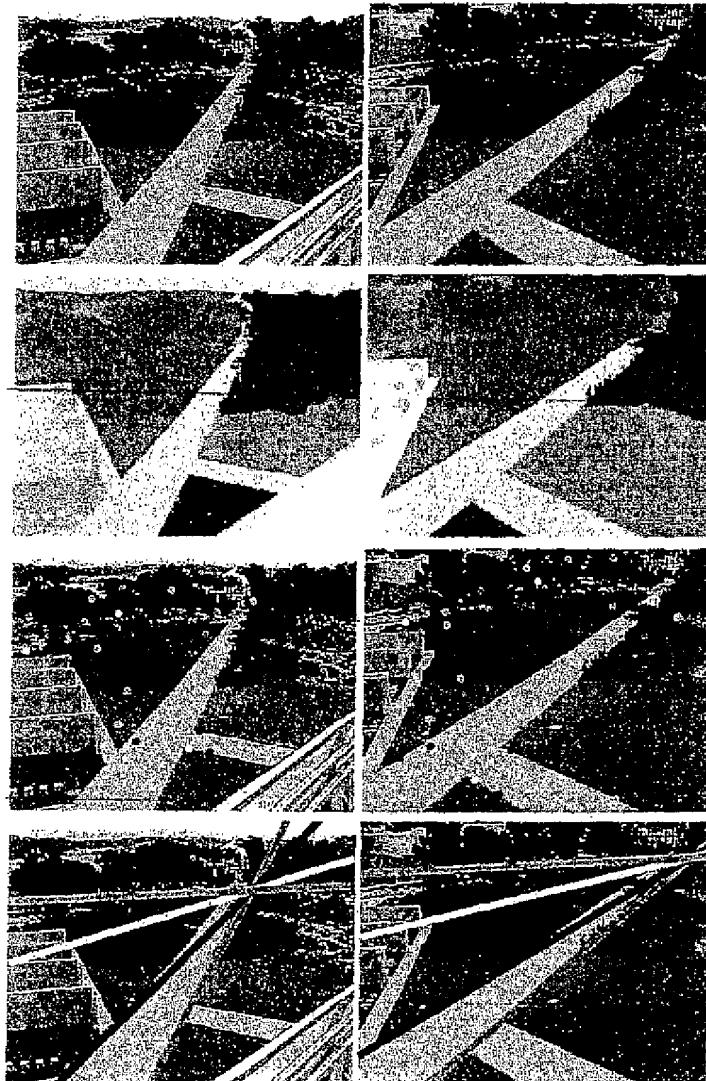


Figure 5. Original images (top), matched aggregates (2nd row), some of the matching aggregates centroids used for RANSAC (3rd row) and epipolar lines (bottom).

5/24

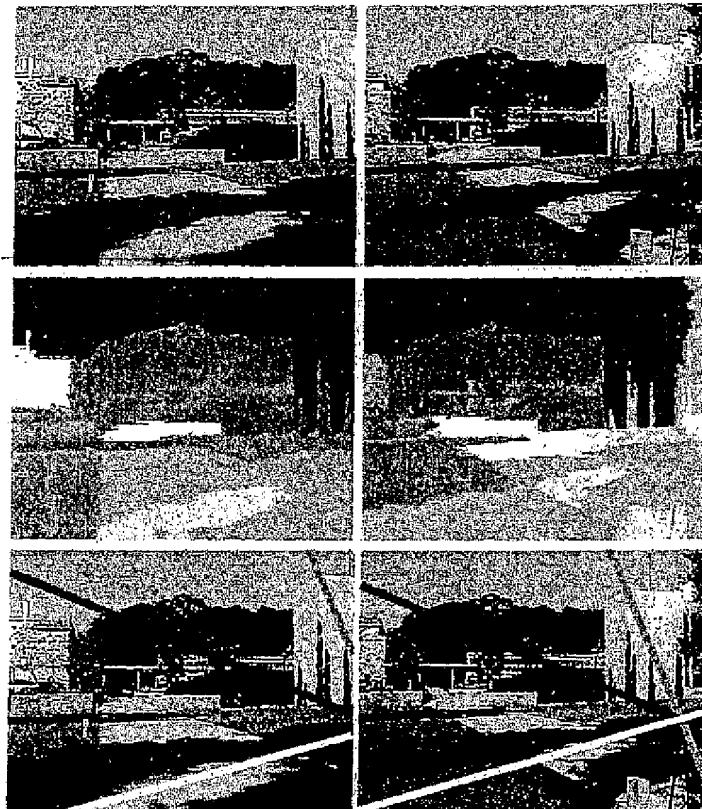


Figure 5 · Original images (top, notice the tripod at the bottom right corner), matched aggregates (middle) and epipolar lines (bottom).

6/24

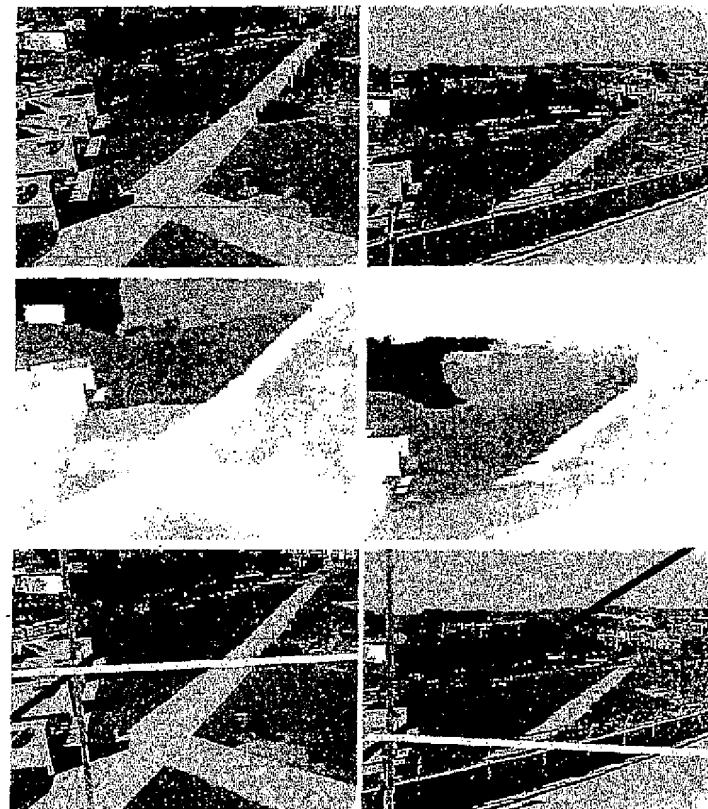


Figure 7 Original images (top, notice the tripod at the bottom left corner), matched aggregates (middle) and epipolar lines (bottom).

7/24

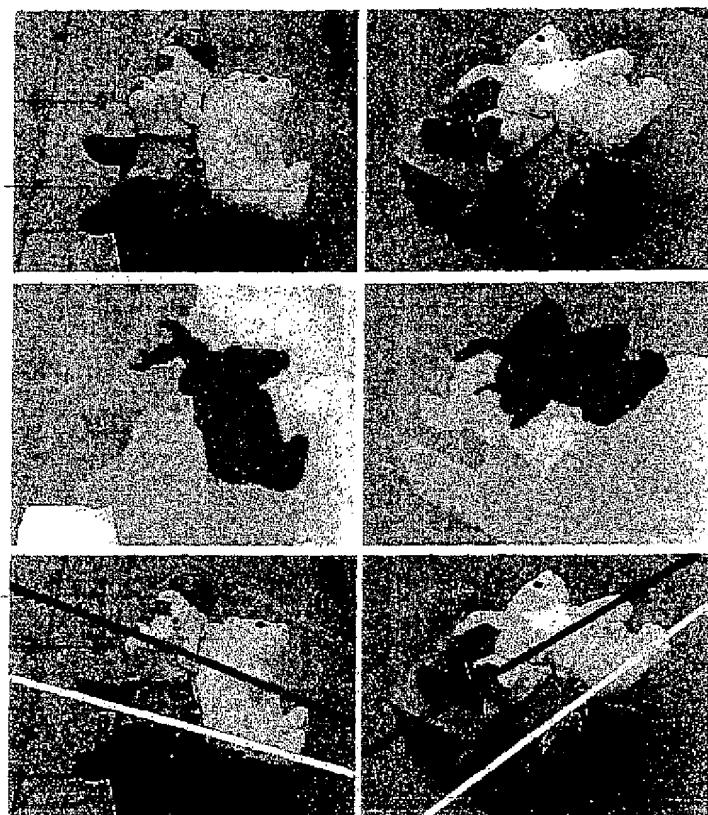


Figure 8 Original images (top), matched aggregates (middle) and epipolar lines (bottom).

8/24

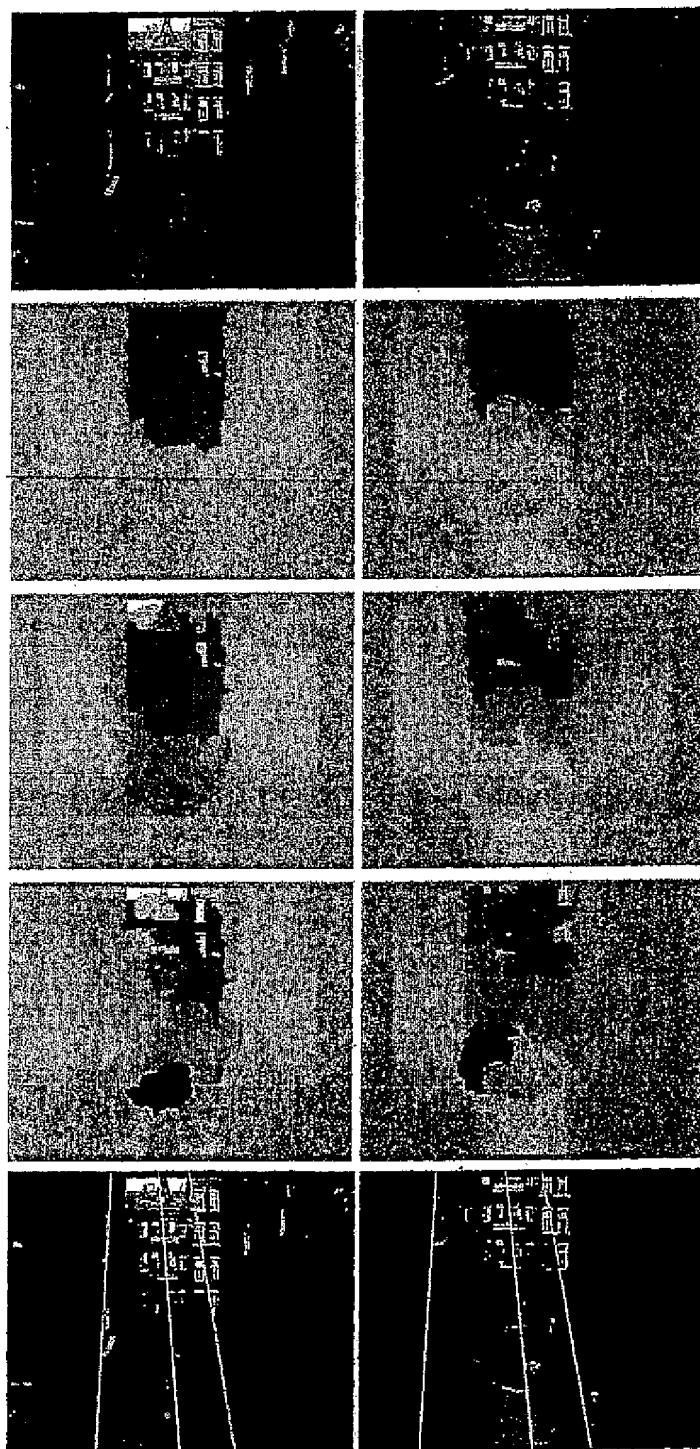


Figure 9 Original images: "Lola1", "Lola2" (top), matched aggregates in scales 10, 9 and 8 (middle) and epipolar lines (bottom).

9/24

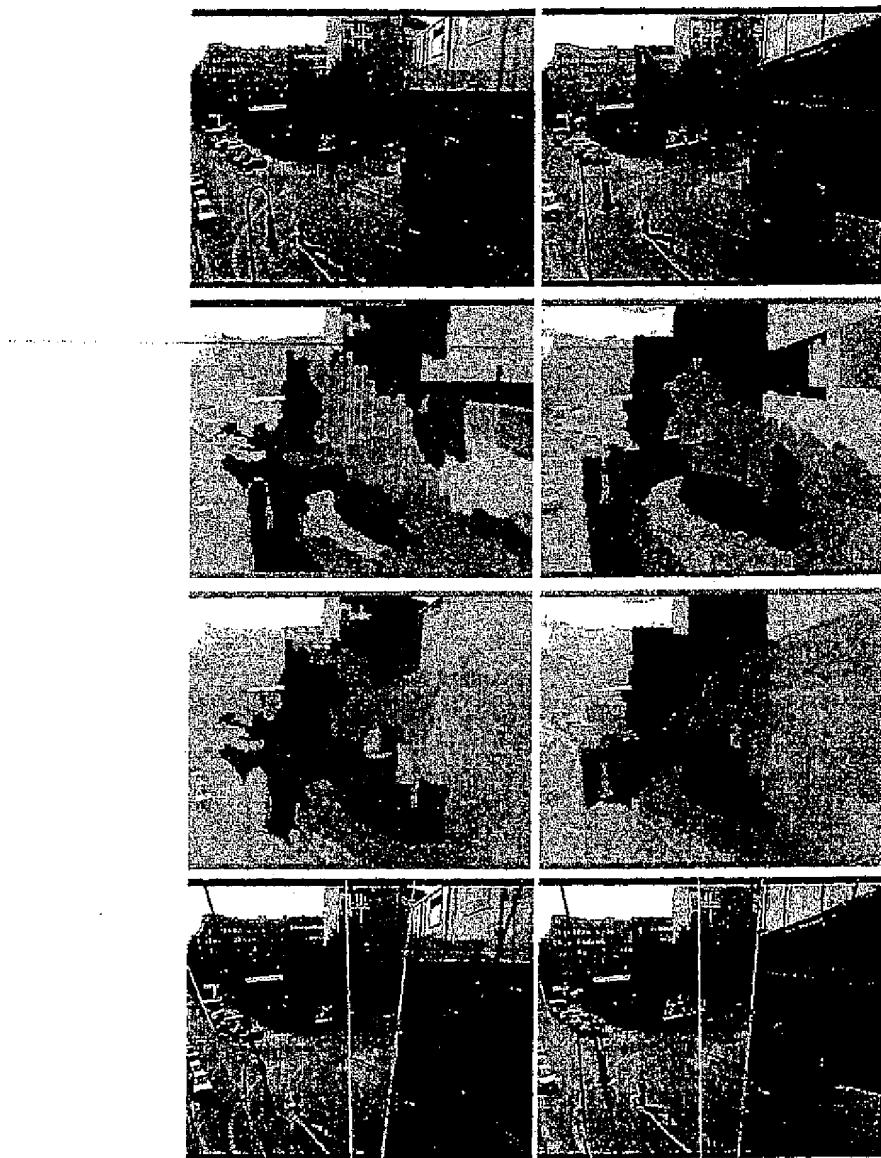


Figure .10: Original images: "Lola3", "Lola4" (top), matched aggregates in scale 9 using: fundamental matrix (2nd row), soft matching (3rd row), and epipolar lines (bottom).

10/24

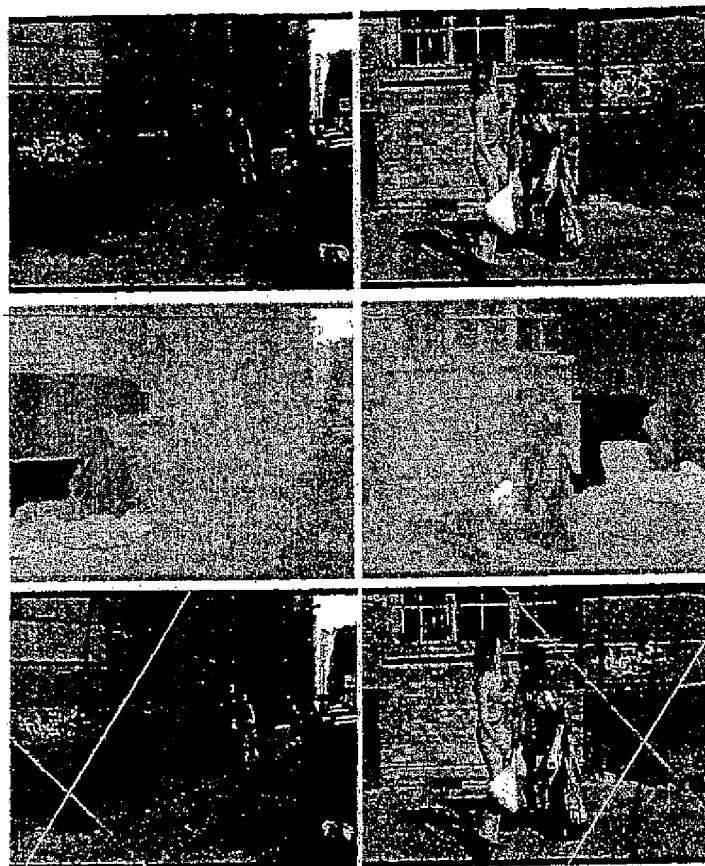


Figure 11: Original images: "Lola5", "Lola6" (top), matched aggregates in scale 9 (middle), and epipolar lines (bottom).

11/24

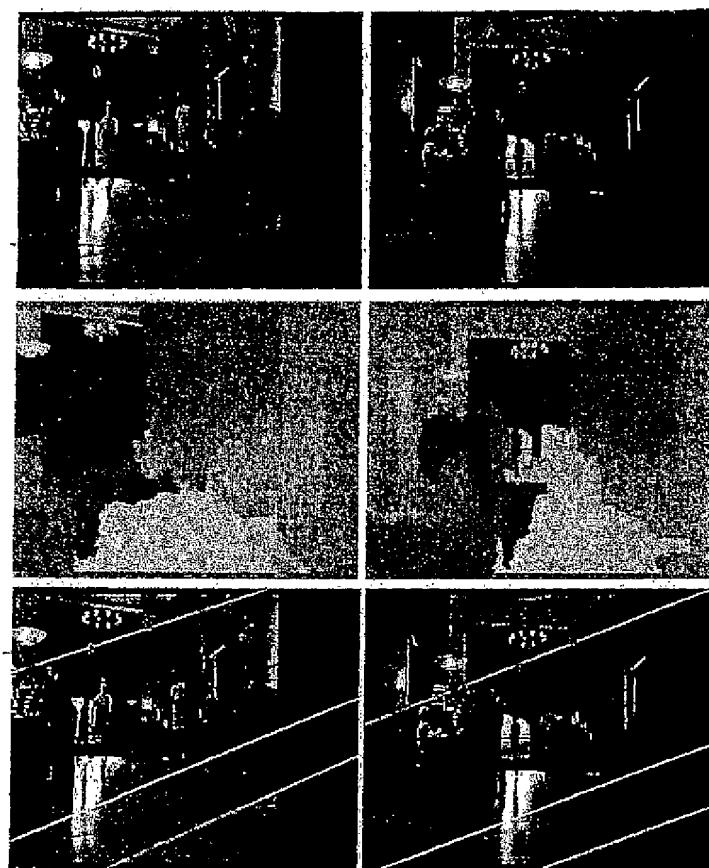


Figure 12: Original images: "Lola7", "Lola8" (top), matched aggregates in scale 9 (middle), and epipolar lines (bottom).

12/24

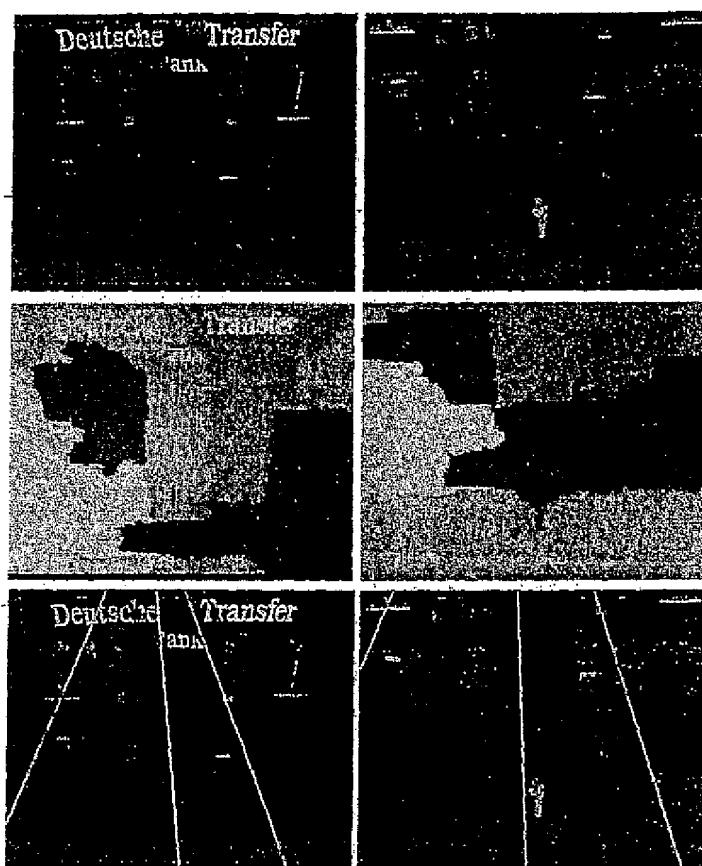


Figure 13: Original images: "Lola9", "Lola10" (top), matched aggregates in scale 10 (middle), and epipolar lines (bottom).

13/24

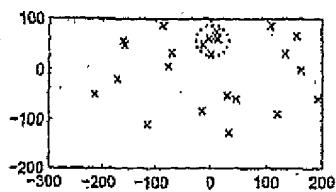


Figure 14: Disparity map of all matches found. Those of the correct matches form a compact cluster (marked by the dotted circle).

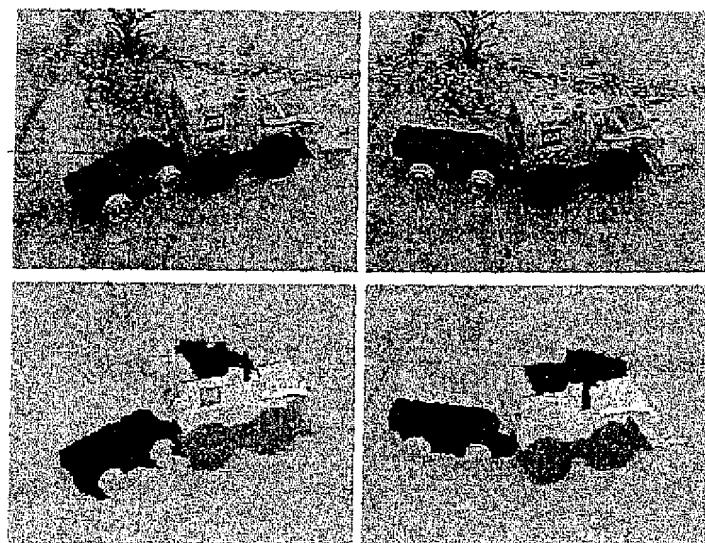


Figure 15: Original images (top) and matched aggregates (bottom).

14/24

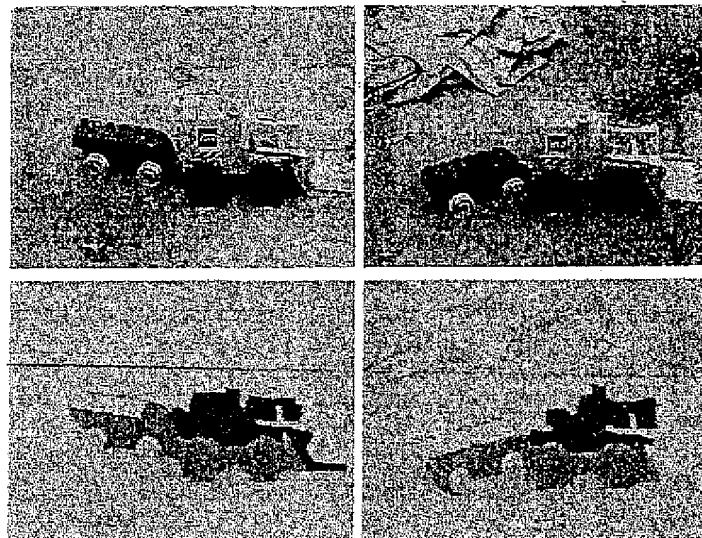


Figure 16: Original images (top) and matched aggregates (bottom).

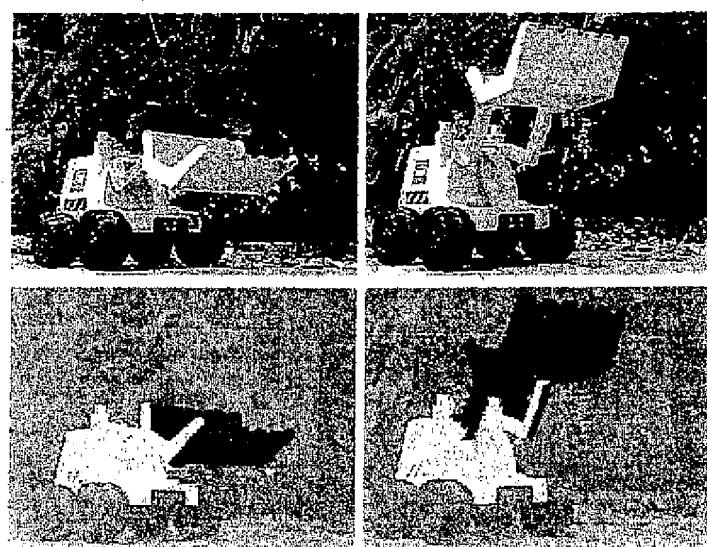


Figure 17: Original images (top) and matched aggregates (bottom).

15/24

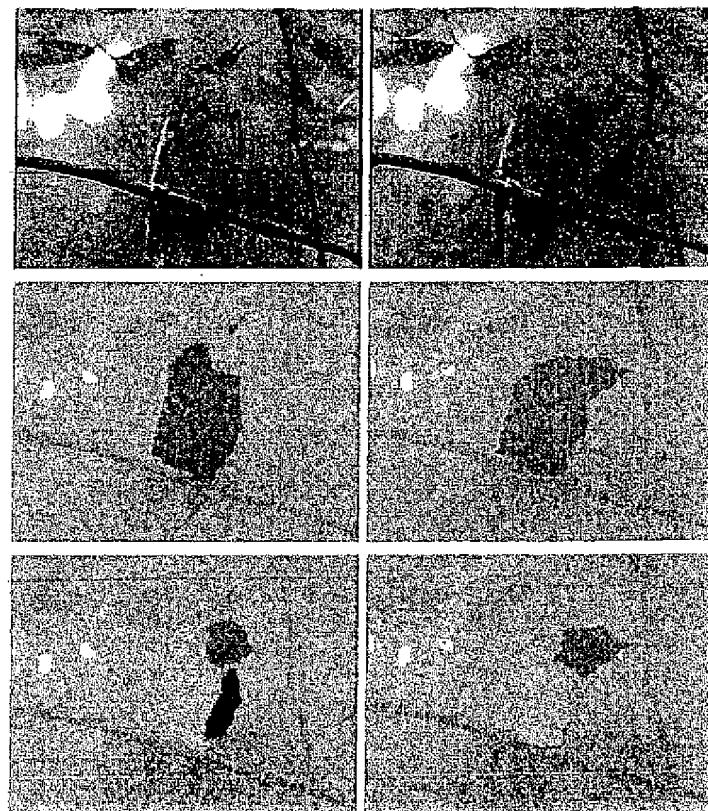


Figure 18: Original images (top), matched aggregates in scale 10 (middle) and in scale 9 (bottom).

16/24

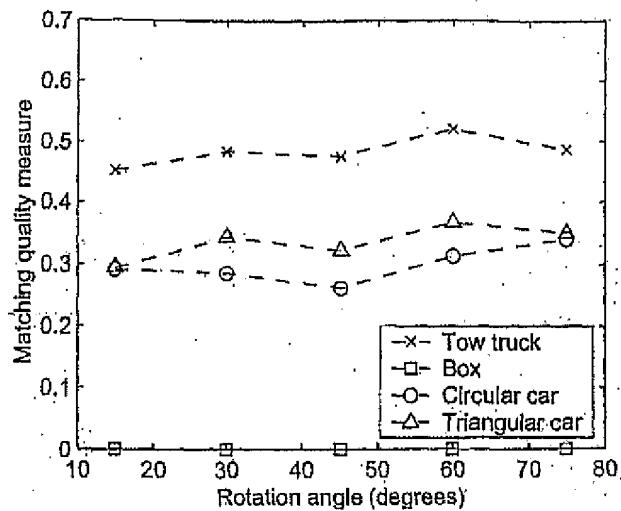


Figure 19: Quality measure for matching the regular car (A) to the other four toys.

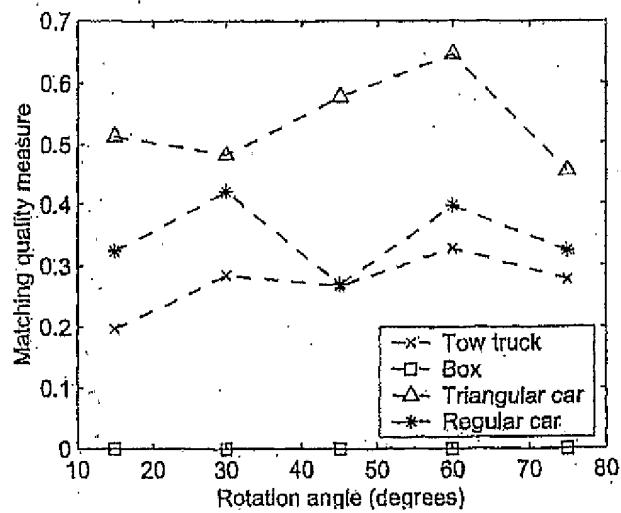


Figure 20: Quality measure for matching the circular car (B) to the other four toys.

17/24.

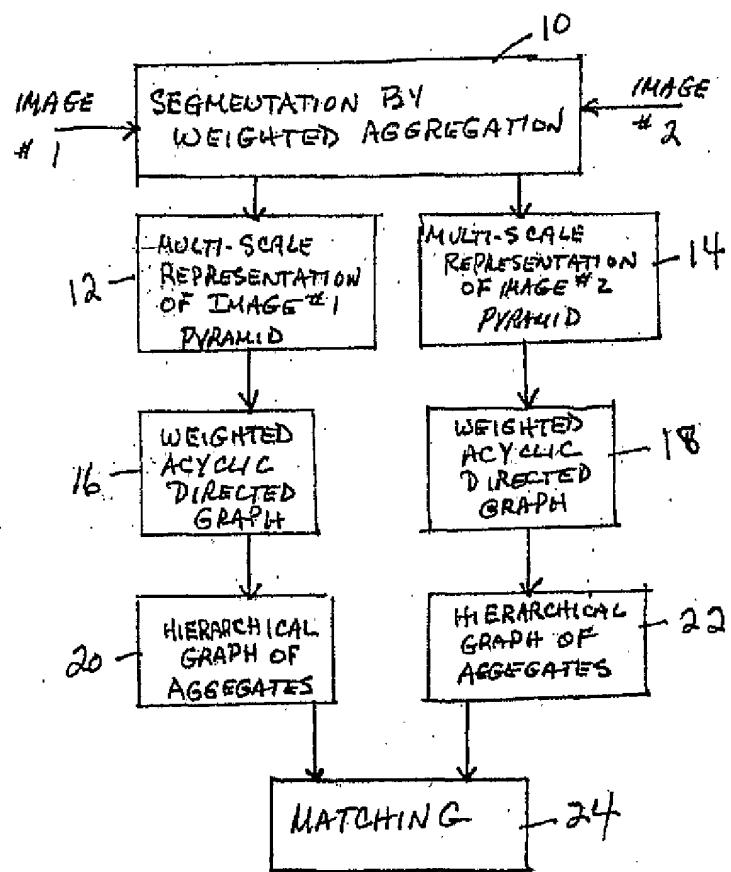


FIGURE 21

18/24

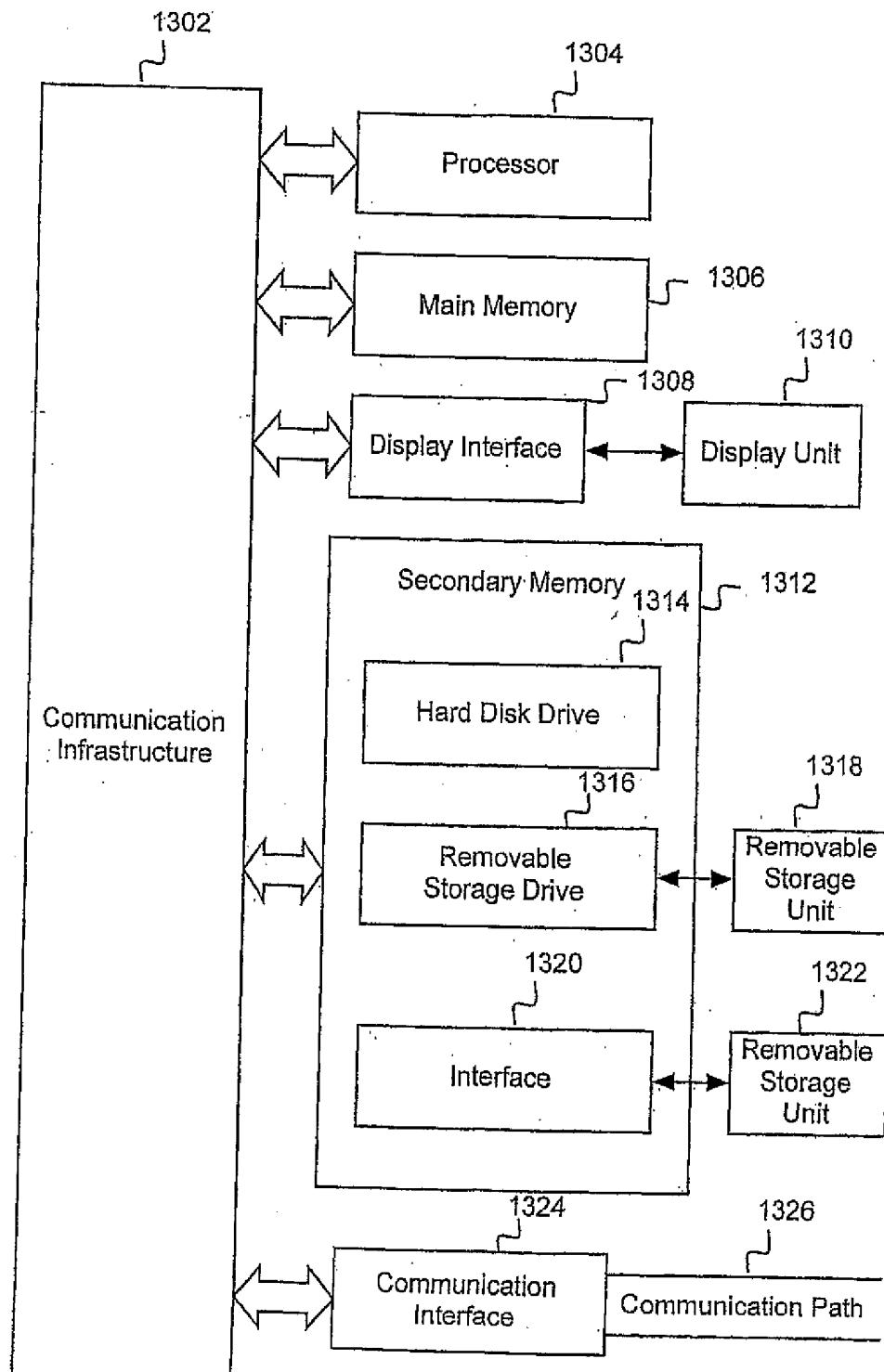


FIG. 22

19/24

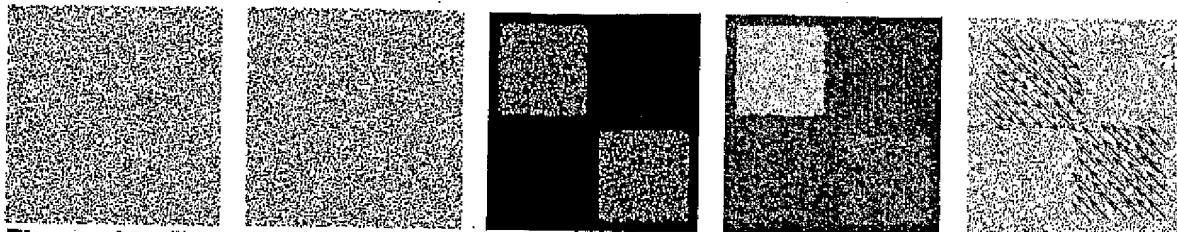


Figure 23: From left to right: a random dot pair containing two translating squares, a difference image, segmentation results obtained with our method, and motion vectors obtained from peaked aggregates at levels 4-5.

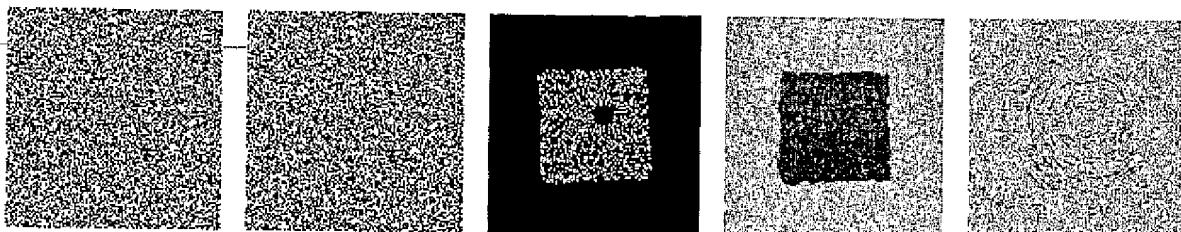


Figure 24: A random dot pair containing a central, rotating square, a difference image, segmentation results obtained with our method, and motion vectors.

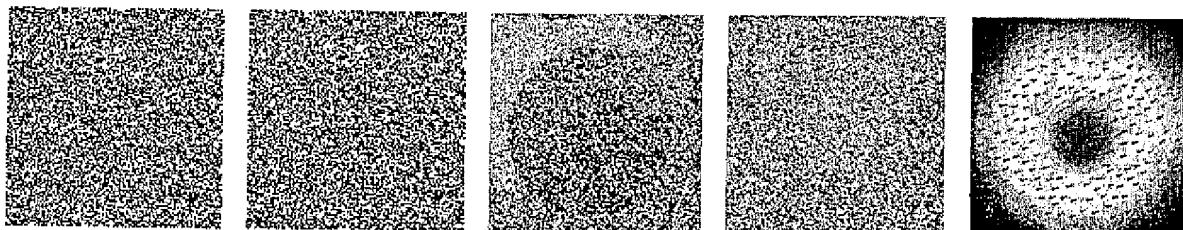


Figure 25: A random dot pair containing two spheres translating in 3D, results obtained by applying our method with affine transformation only, results obtained by applying a comparison of fundamental matrices at the coarsest levels, and motion vectors overlaid on a depth image (intensity proportional to distance from camera).

20/24

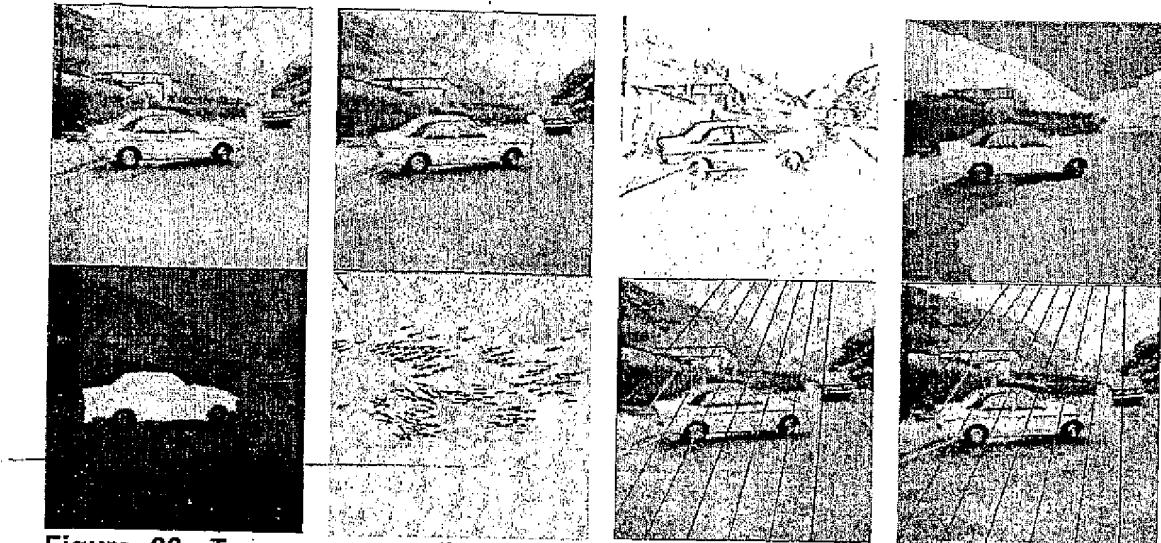


Figure 26: Top row: a motion pair, a difference image, results obtained by applying segmentation based on intensity cues alone. Bottom row: results obtained by applying our method with both motion and intensity cues, motion vectors, and epipolar lines computed for the background segment.



Figure 27: A motion pair, a difference image, results obtained by applying segmentation based on intensity cues alone, results obtained by applying our method with both motion and intensity cues, and motion vectors.

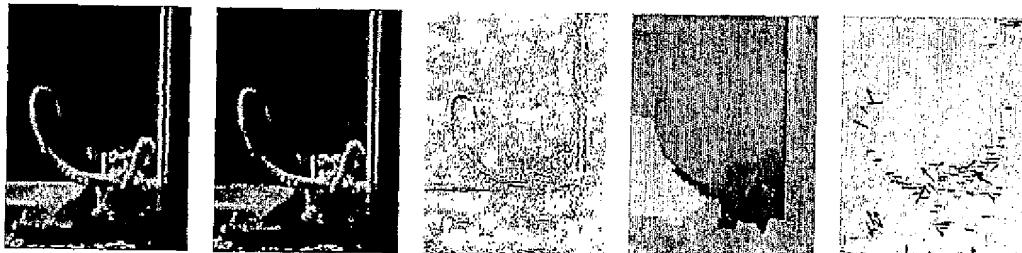


Figure 28: A motion pair, a difference image, results obtained by applying our segmentation method, and motion vectors.

21/24

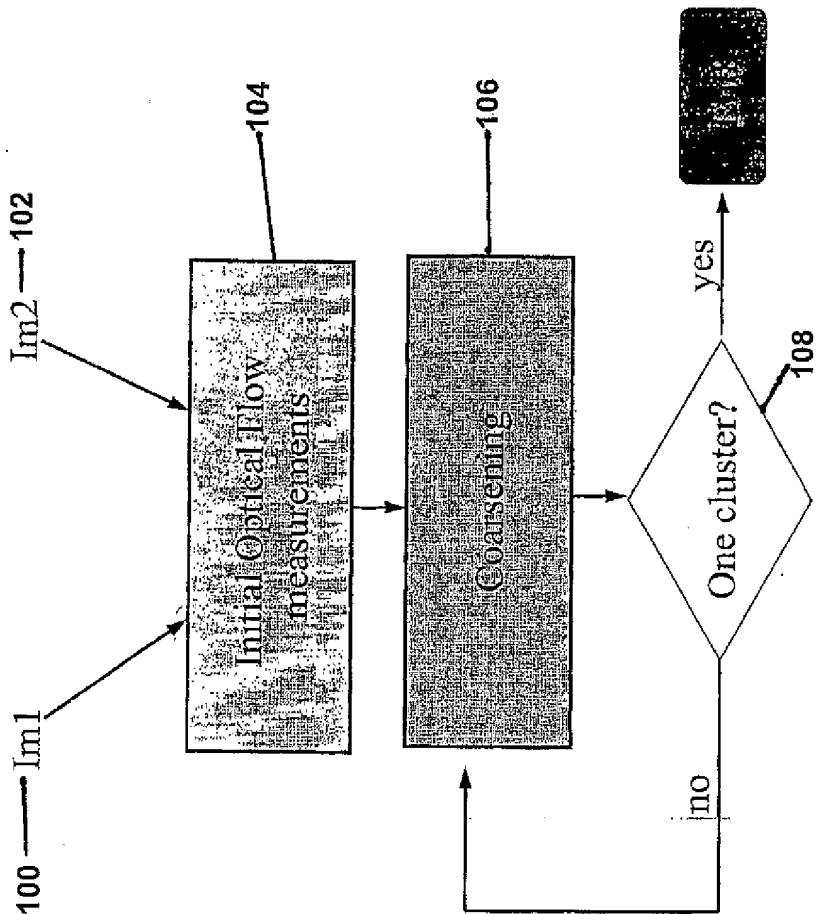
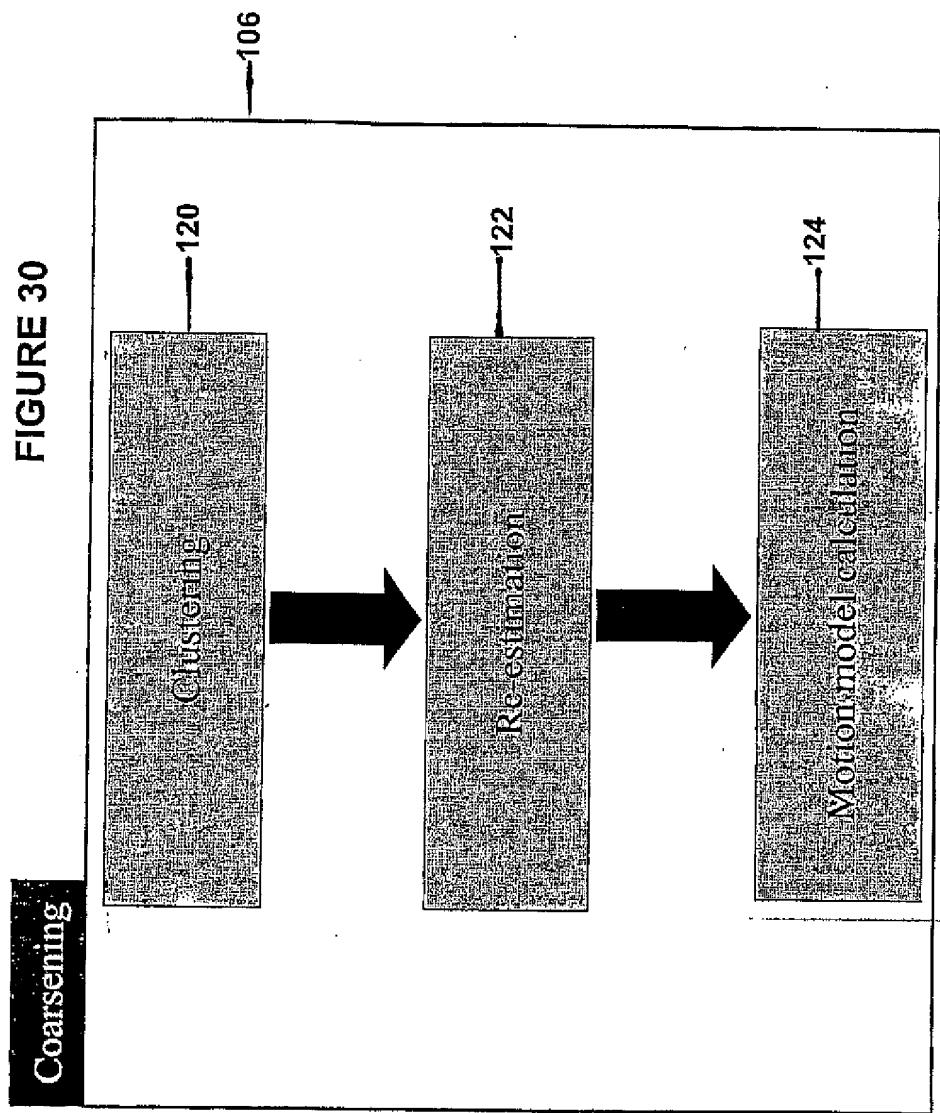


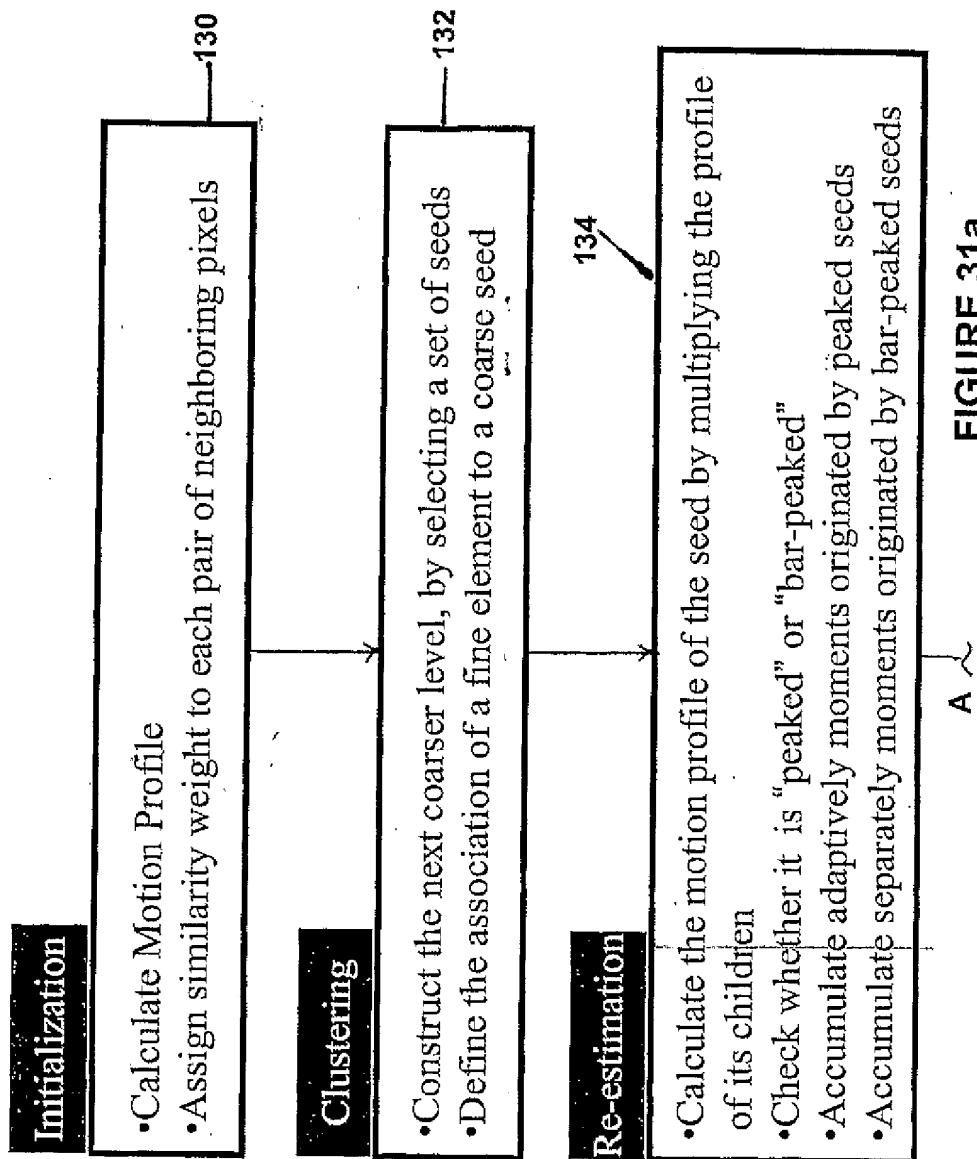
FIGURE 29

22/24

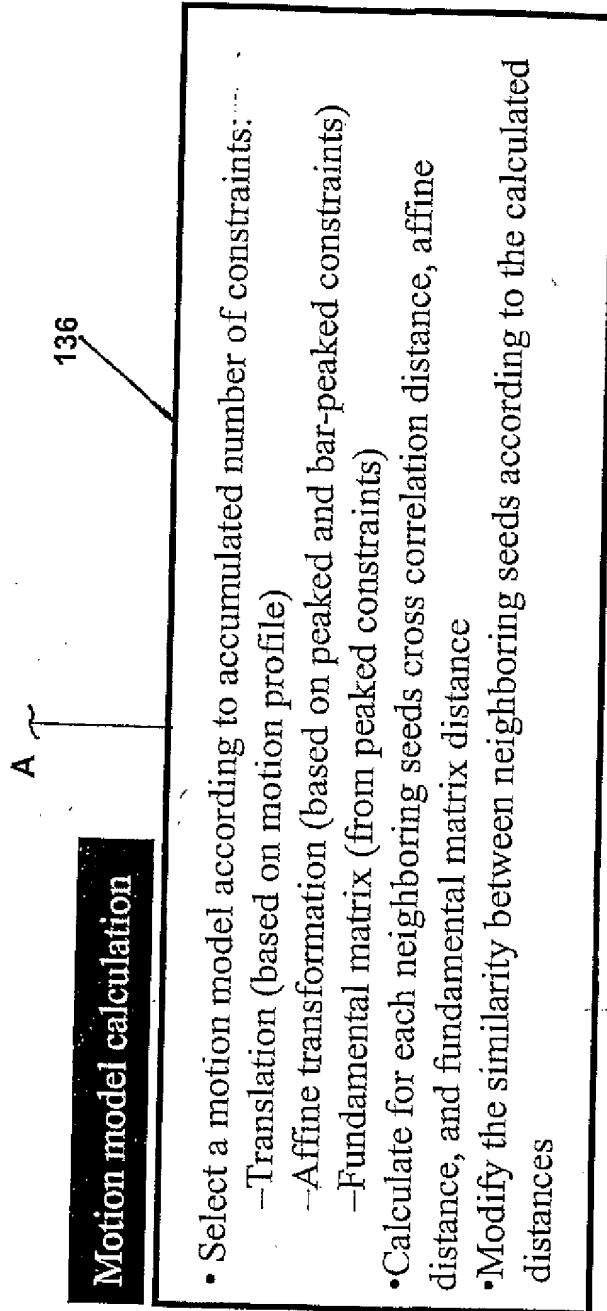
FIGURE 30



23/24



A ↗ FIGURE 31a

24/24**FIGURE 31b**